

**AMENDMENTS TO THE CLAIMS**

**This listing of claims will replace all prior versions and listings of claims in the application:**

**LISTING OF CLAIMS:**

1. (currently amended): An optimum command producing apparatus configured to receive a command, process the command in such a manner that a controlled object implements a desirable operation and output an optimum command value to a servo control apparatus, the apparatus comprising:

an N-order filter processing section configured to carry out an N-order filter processing for the command and calculate values from a 1<sup>st</sup> order differential value to an (N-1)<sup>th</sup> order differential value of the command subjected to the filter processing, wherein N is an integer of 2 or more; and

an arithmetic unit configured to calculate a value obtained by multiplying each of the values calculated by the N-order filter processing section by a corresponding one of gains, and wherein N is set to be equal to or greater than a value defined by subtracting an order of the command from an order of denominator of a transfer function of an approximation model that represents the controlled object with Laplace operator

where N is based on a transfer function from a motor position of a control object to the load position with Laplace operator,

wherein the N-order filter processing is not based on control parameters.

2. (currently amended): An optimum command producing apparatus configured to receive a command, process the command in such a manner that a controlled object implements

a desirable operation and output an optimum command value to a servo control apparatus, the apparatus comprising:

an N-order filter processing section configured to carry out an N-order filter processing for the command and calculating values from a 1<sup>st</sup> order differential value to an (N-1)<sup>th</sup> order differential value of the command subjected to the filter processing, wherein N is an integer of 2 or more;

an arithmetic unit configured to calculate a value obtained by multiplying each of the values calculated by the N-order filter processing section by a corresponding one of gains; and

an M-order filter processing section configured to perform an M-order filter processing the value calculated by the arithmetic unit wherein M is an integer of 1 or more,

where N is based on a transfer function from a motor position of a control object to the load position with Laplace operator,

wherein the N-order filter processing is not based on control parameters

~~wherein N is set to be equal to or greater than a value defined by subtracting an order of the command from an order of denominator of a transfer function of an approximation model that represents the controlled object with Laplace operator.~~

3. (currently amended): An optimum command producing apparatus configured to receive a command, process the command in such a manner that a controlled object implements a desirable operation and output an optimum command value to a servo control apparatus, the apparatus comprising:

an N-order filter processing section configured to carry out an N-order filter processing for the command and calculate values from a 1<sup>st</sup> order differential value to an L<sup>th</sup> order

differential value of the command subjected to the filter processing, wherein N is an integer of 2 or more and L is an integer of 1 or more; and

an arithmetic unit configured to multiply each of the values calculated by the N-order filter processing section by a corresponding one of gains, and then sum all of the resulting products,

wherein L is an order of denominator of a transfer function of an approximation model that represents the controlled object with Laplace operator, and

where N is based on a transfer function from a motor position of a control object to the load position with Laplace operator,

wherein the N-order filter processing is not based on control parameters

~~wherein N is set to be equal to or greater than a value defined by subtracting an order of the command from L.~~

4. (canceled).

5. (previously presented): The optimum command producing apparatus according to any one of claims 1 to 3, wherein a recursive type filter or a non-recursive type filter is used for the N-order filter.

6. (previously presented): The optimum command producing apparatus according to any one of claims 1 to 3, wherein the optimum command value is one of a position command, a speed command, an acceleration command and a torque command or a combination thereof.